

FIG.1

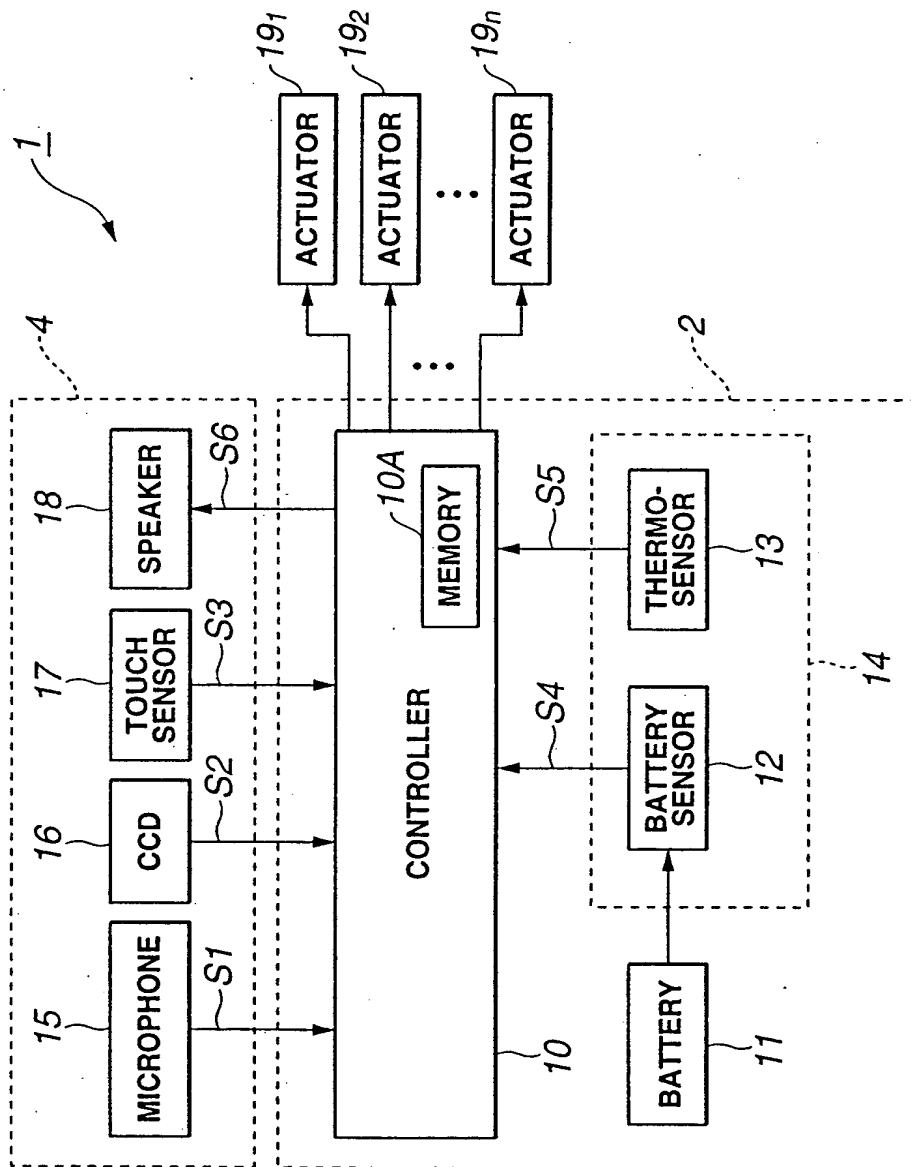


FIG.2

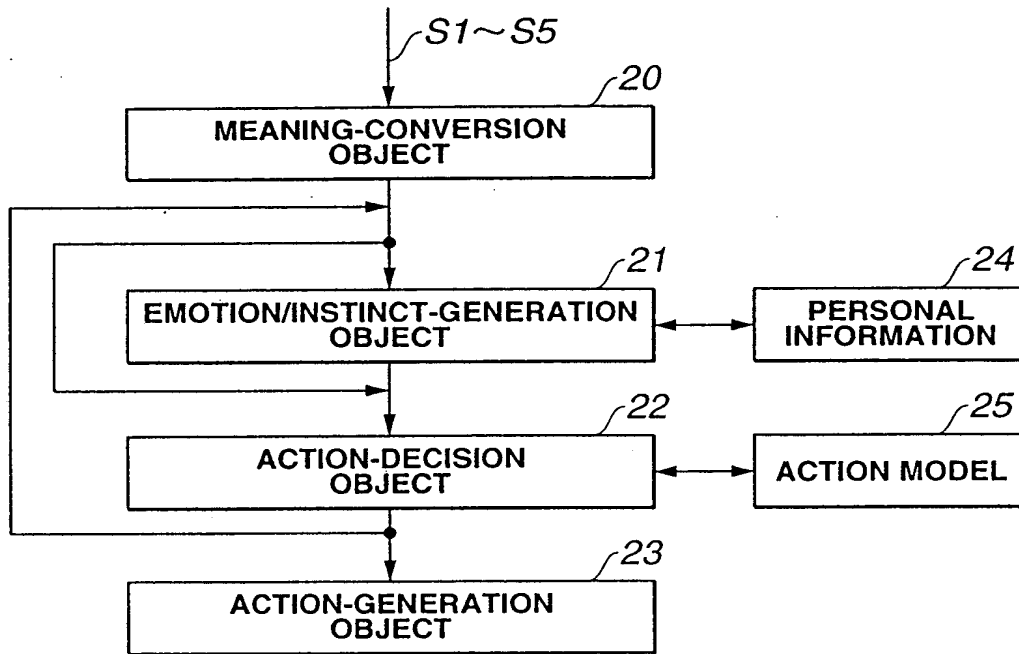


FIG.3

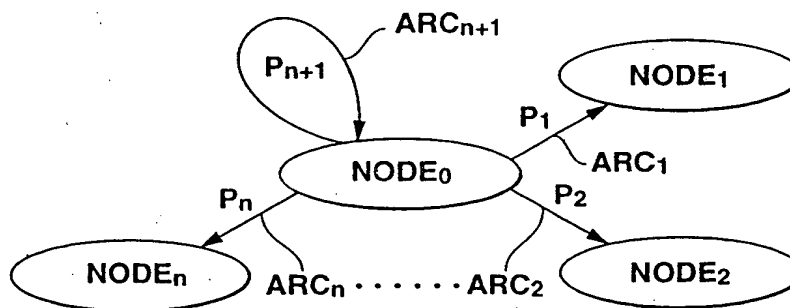


FIG.4

NODE ₁₀₀		NODE ₁₂₀			PROBABILITY OF TRANSITION TO OTHER NODE (Di)			
NODE 100	INPUT EVENT NAME	DATA NAME	DATA RANGE					
TRANSITION DESTINATION NODE				NODE 120	NODE 120	NODE 1000		NODE 600
OUTPUT ACTION				ACTION 1	ACTION 2	MOVE BACK		ACTION 4
1	BALL	SIZE	0, 1000	30%				
2	PAT				40%			
3	HIT				20%			
4	MOTION					50%		
5	OBSTACLE	DISTANCE	0, 100			100%		
6		JOY	50, 100					
7		SURPRISE	50, 100					
8		SADNESS	50, 100					

FIG.5

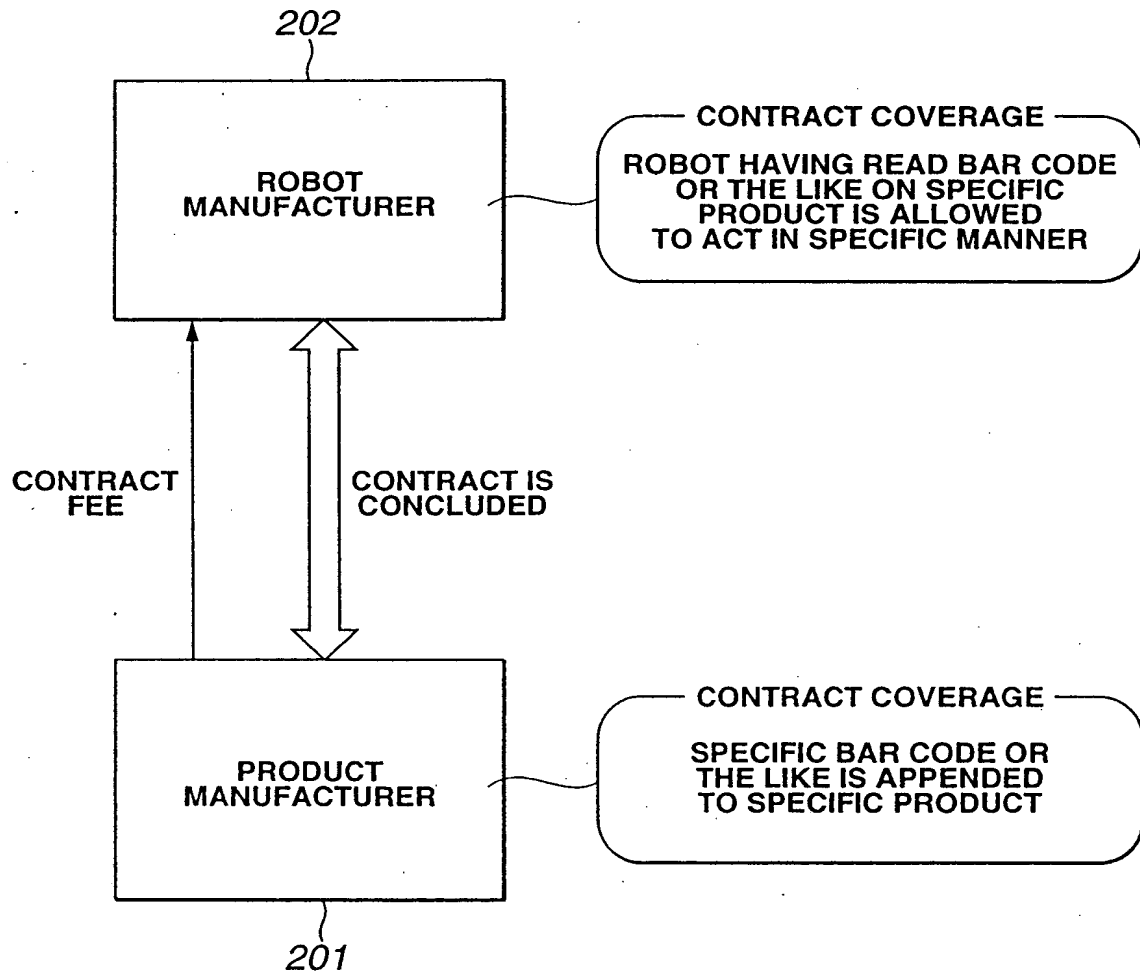


FIG.6

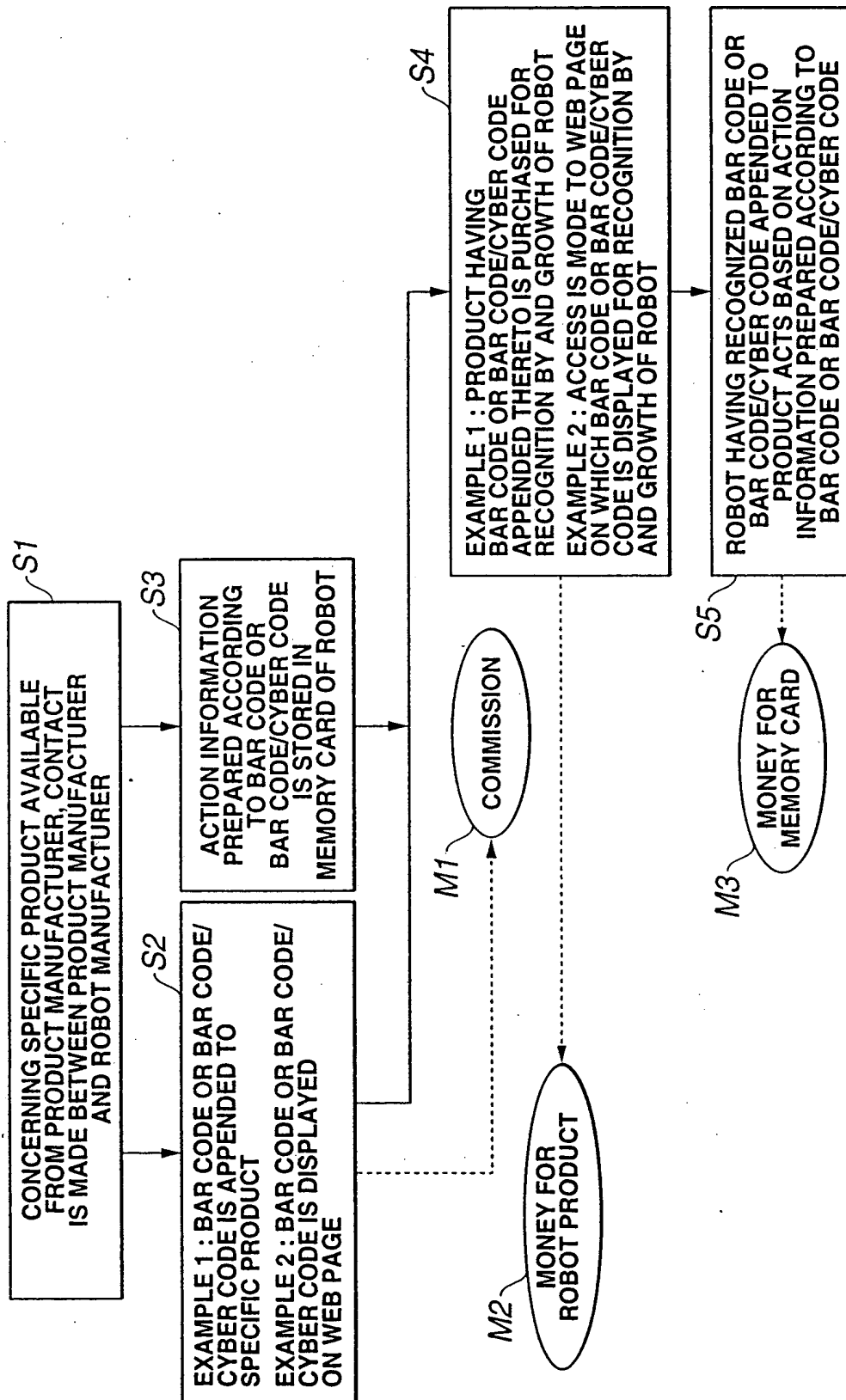


FIG.7

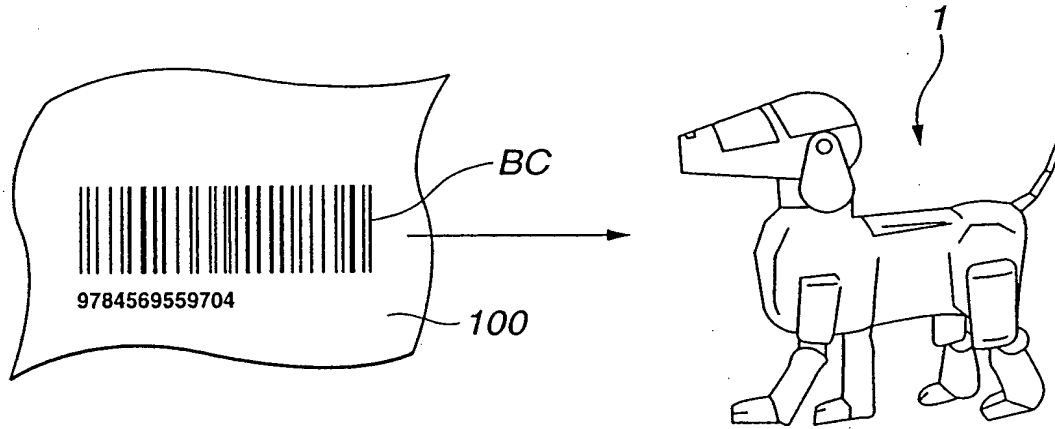


FIG. 8A

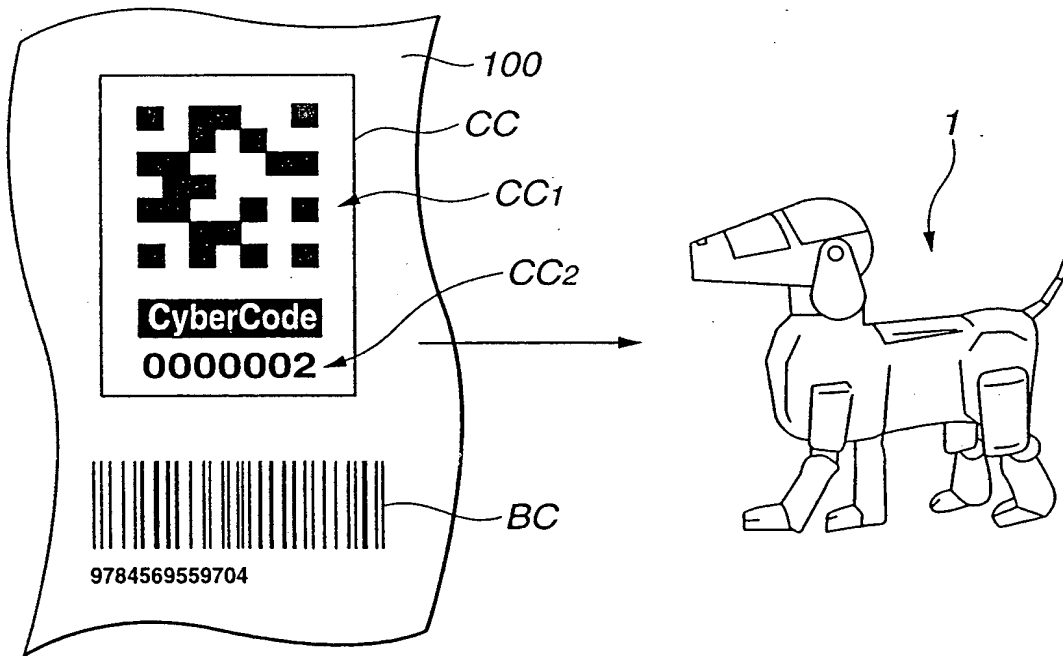


FIG. 8B

FIG.9A

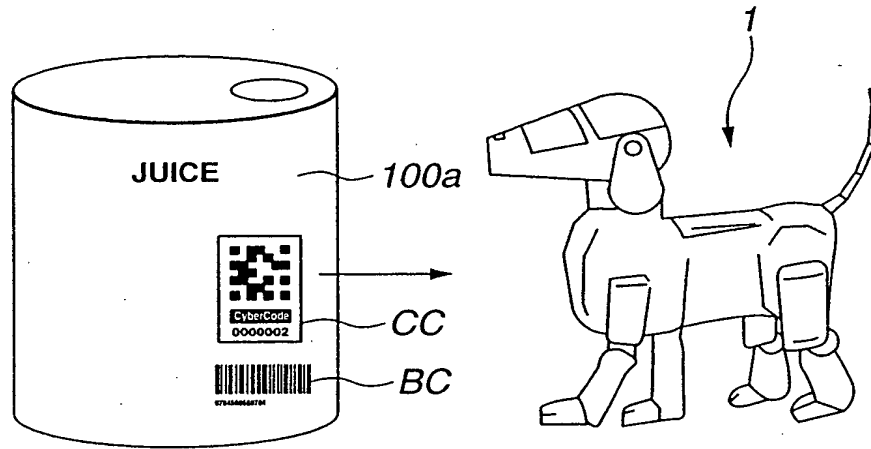


FIG.9B

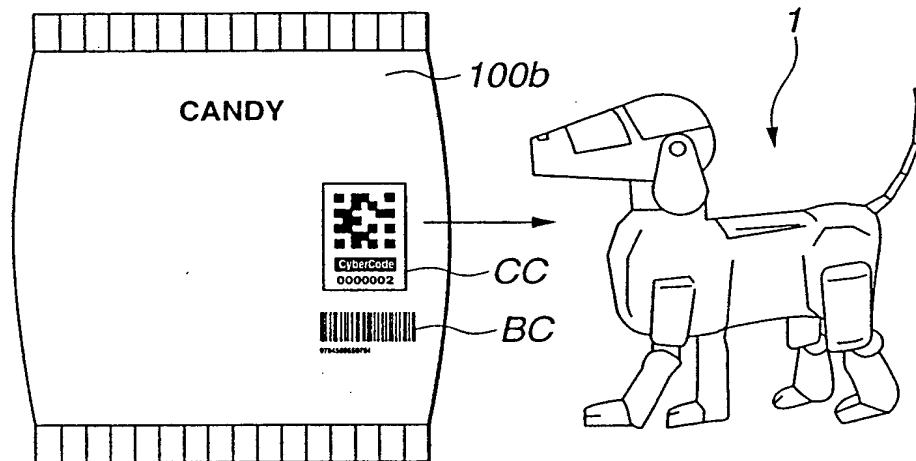
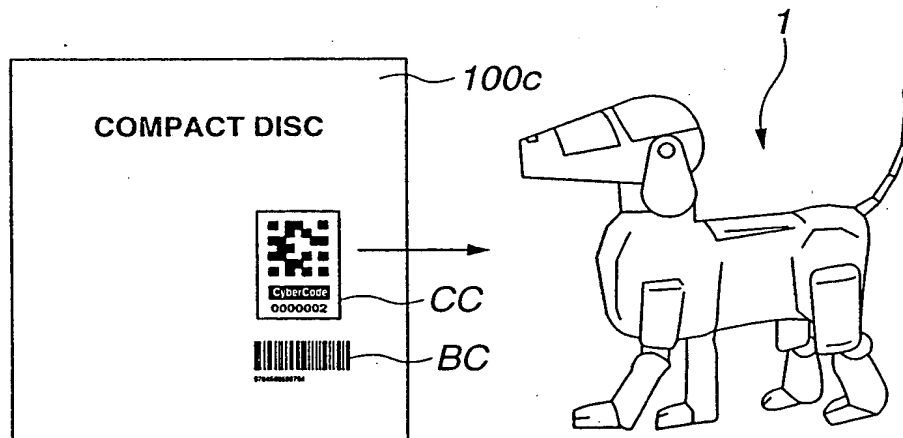


FIG.9C



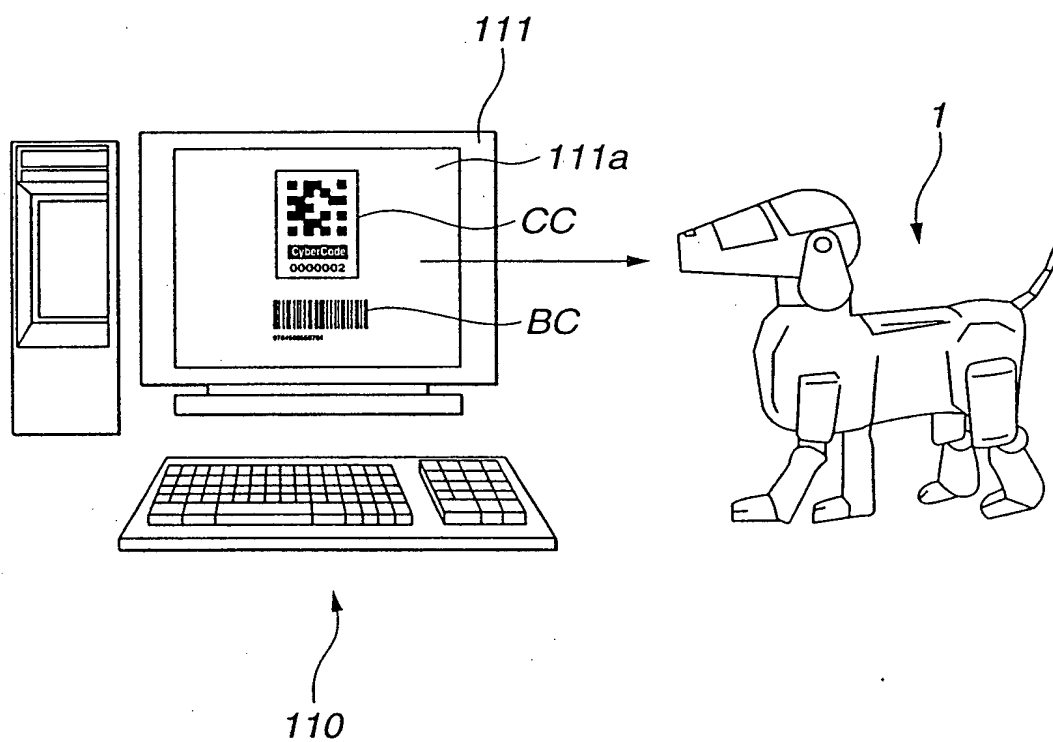


FIG.10

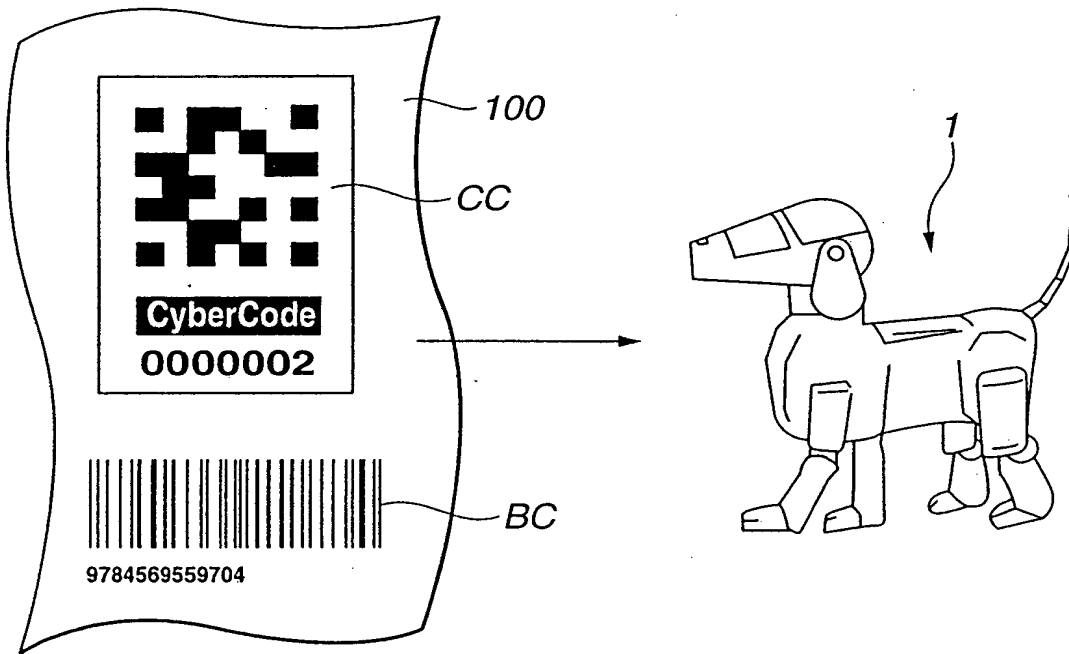


FIG. 11A

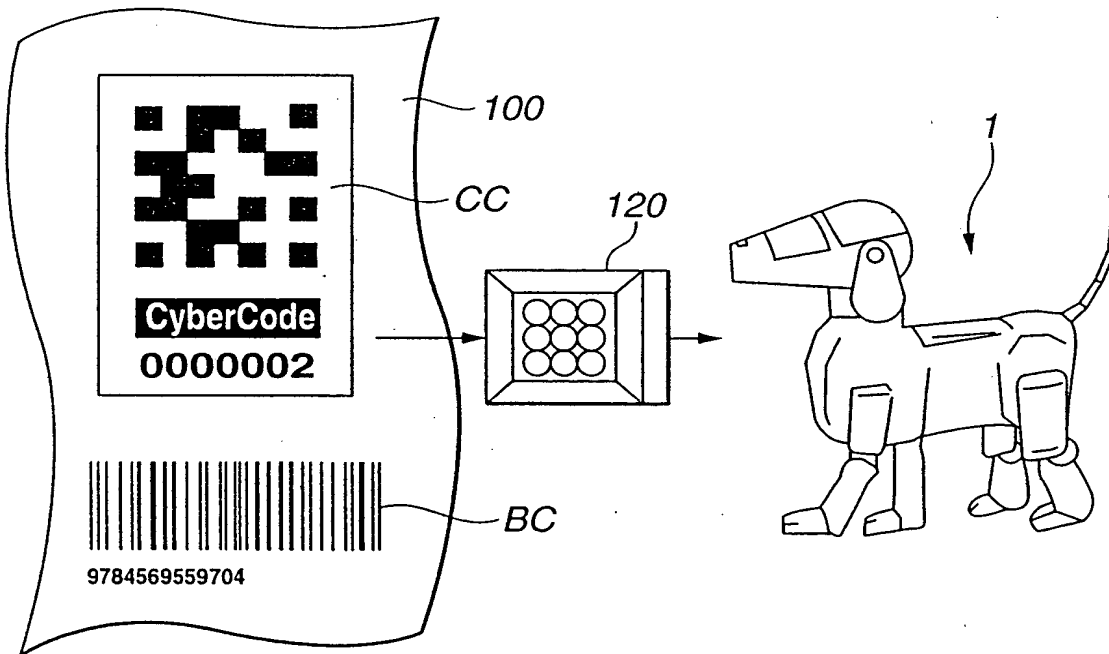


FIG. 11B

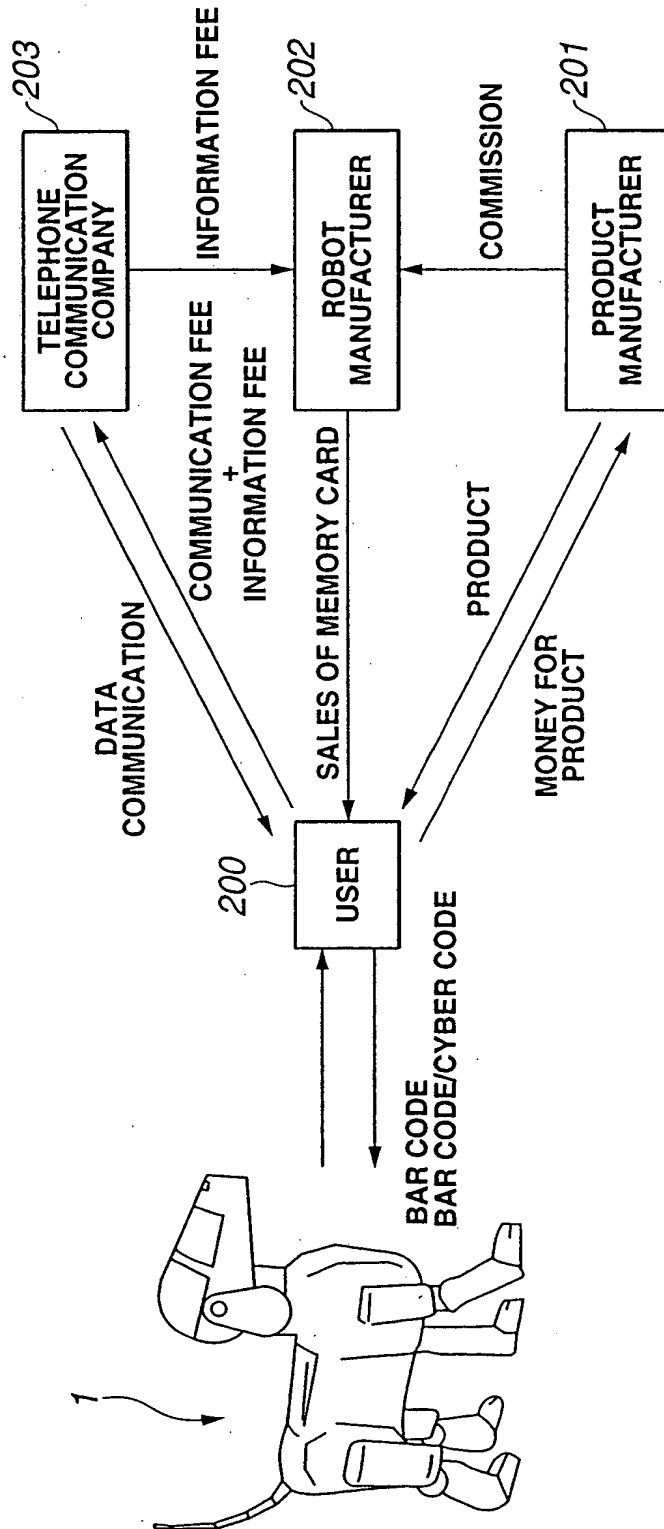


FIG.12

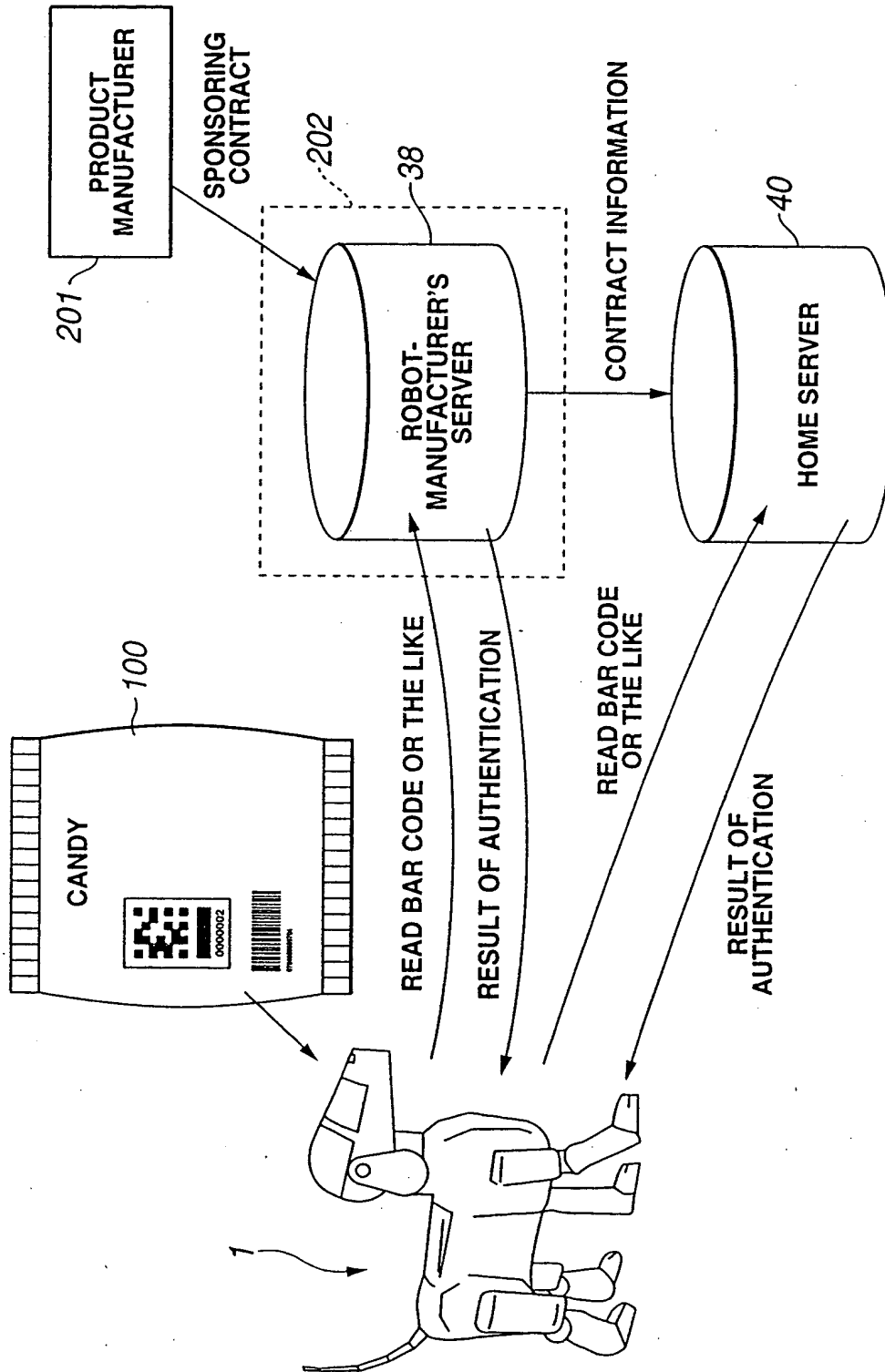


FIG.13

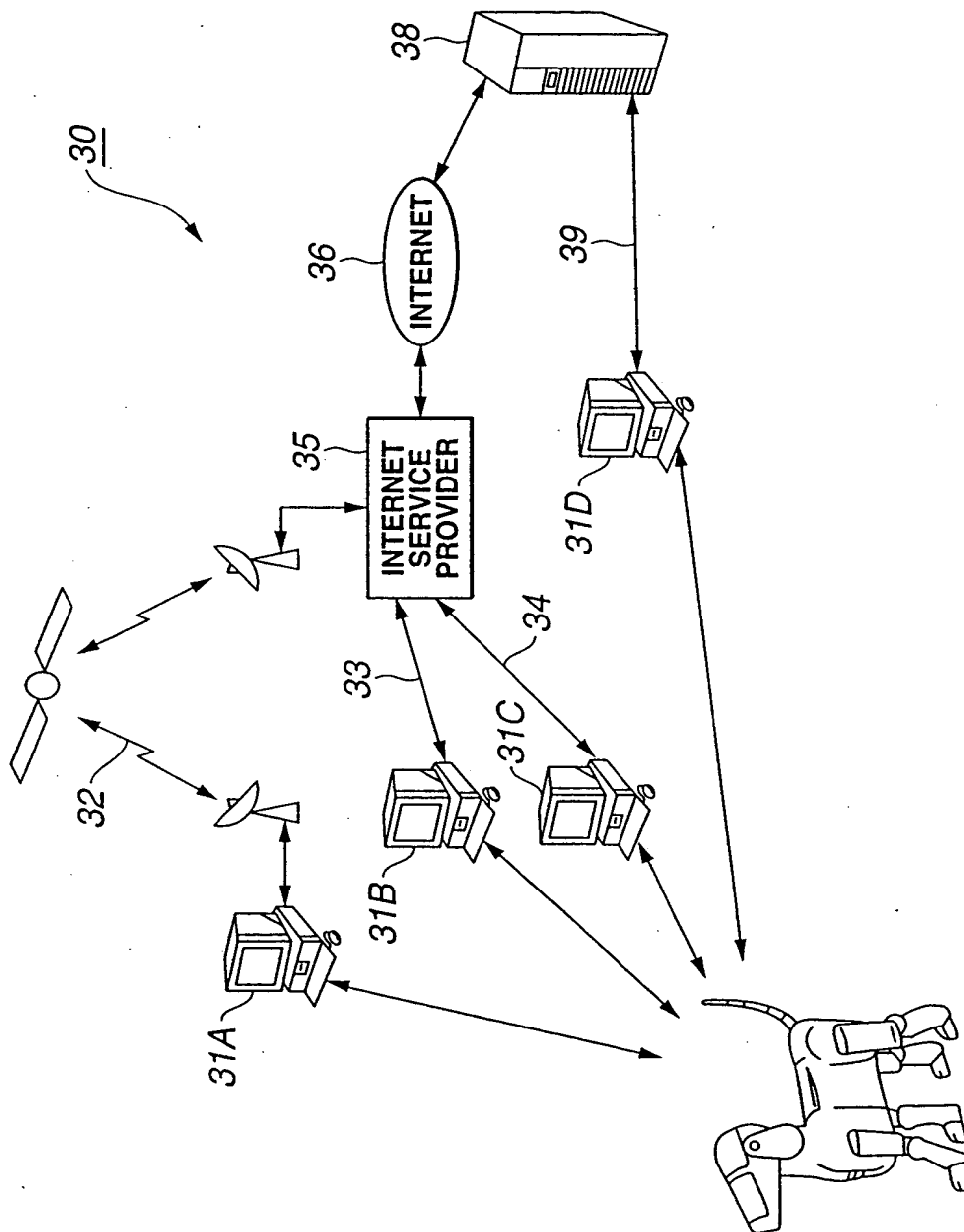


FIG.14

ROBOT-ACCESSORY MANUFACTURER ROBOT MANUFACTURER USER

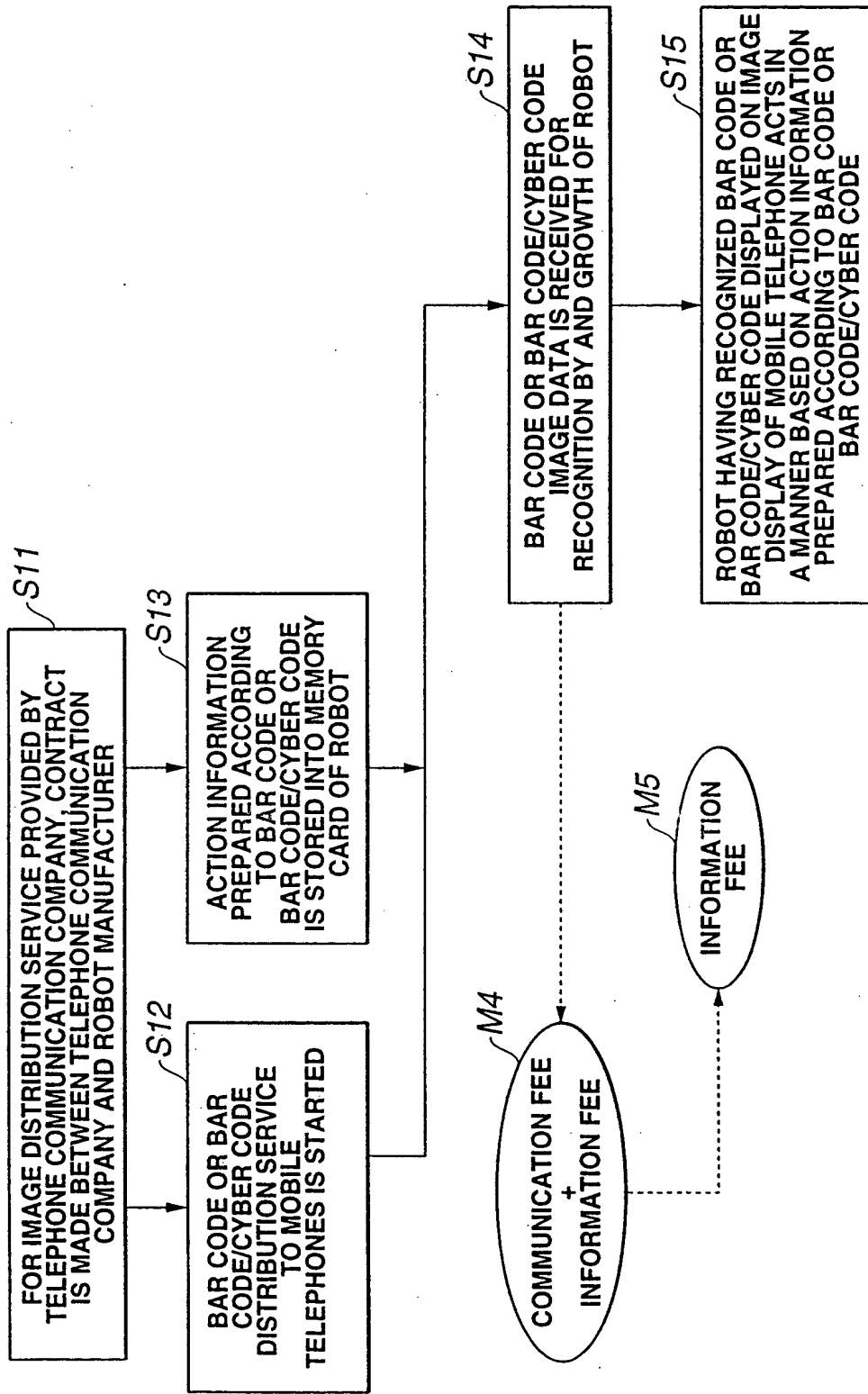


FIG.15

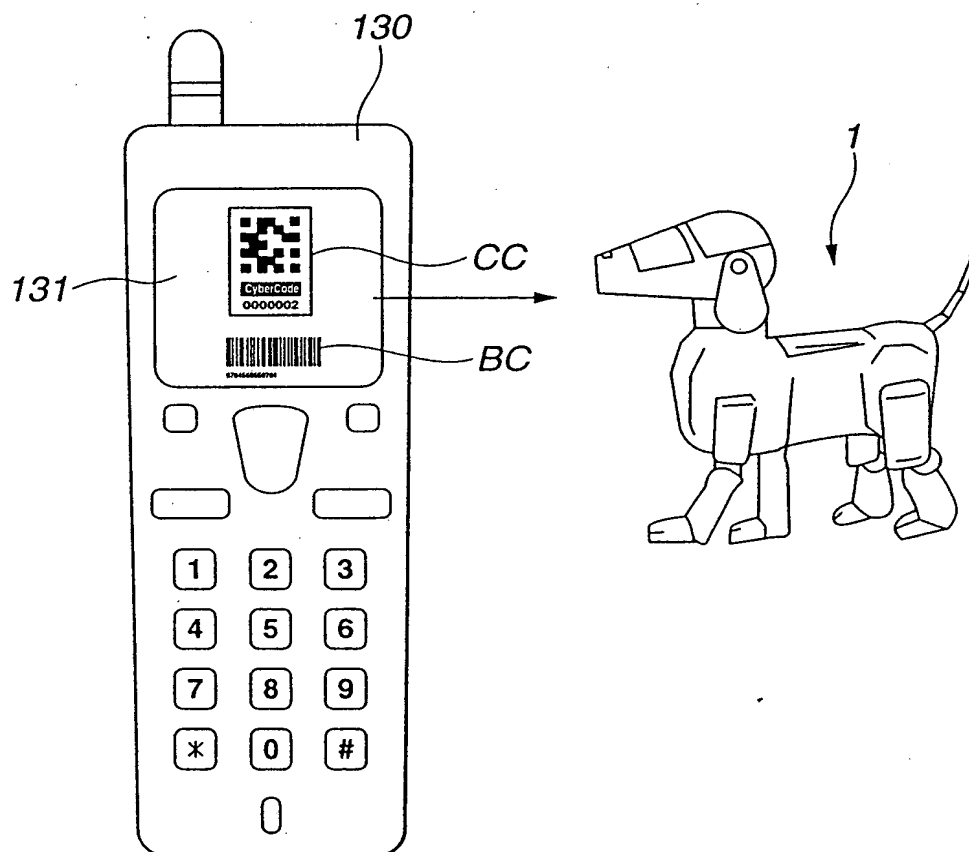


FIG.16

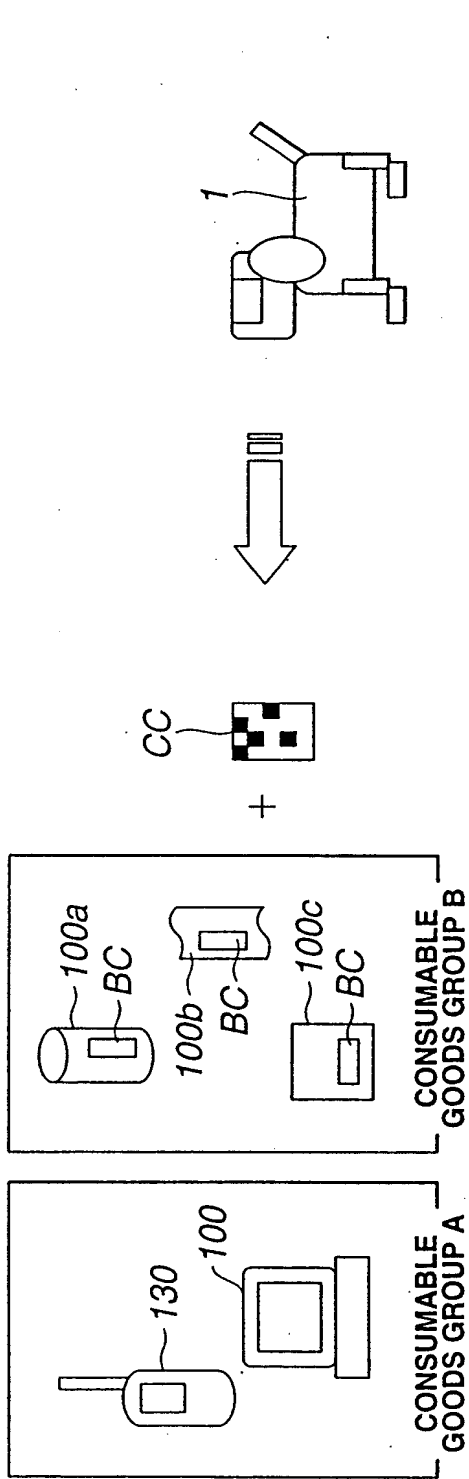


FIG. 17A

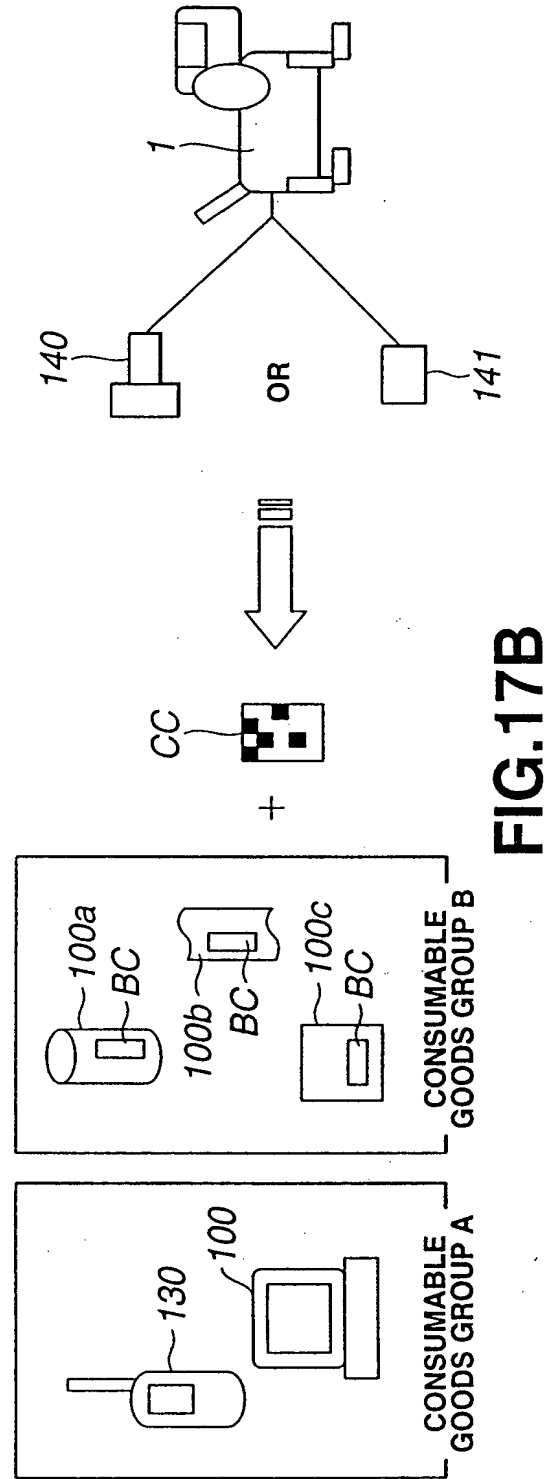


FIG. 17B